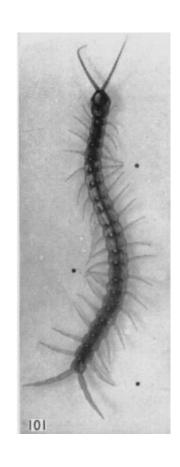
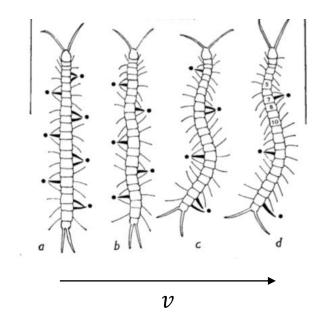
Motivation





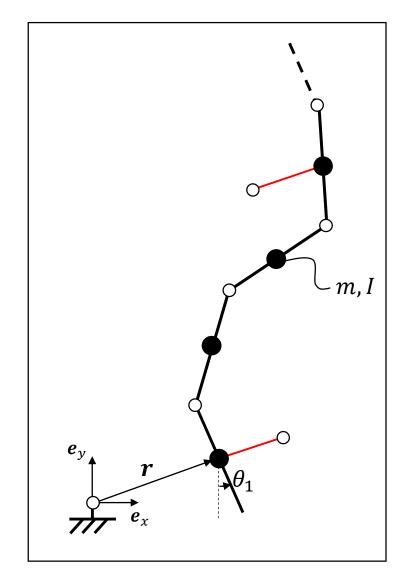


- (Manton, 1977): Undulations are due to stepping pattern and deleterious¹
- (Anderson, 1995): Undulations actively supported by muscles²

Fig. S. M. Manton, Zool. J. Linnean. Soc. 45, 306-07 (1965).

- 1 S. M. Manton, Oxford: Clarendon Press (1977).
- 2 B. D. Anderson, J. W. Shultz, and B. C. Jayne, J. Exp. Biol. 198, 1185 (1995).

Model



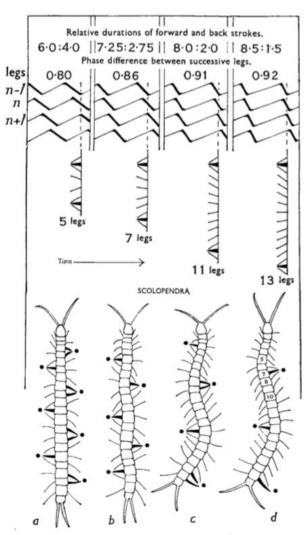
 Chain of 21 rigid bodies in transverse plane

$$\mathbf{M}\ddot{\mathbf{q}} = \mathbf{F} + \mathbf{J}_{\mathrm{c}}^{T} \boldsymbol{\lambda}$$

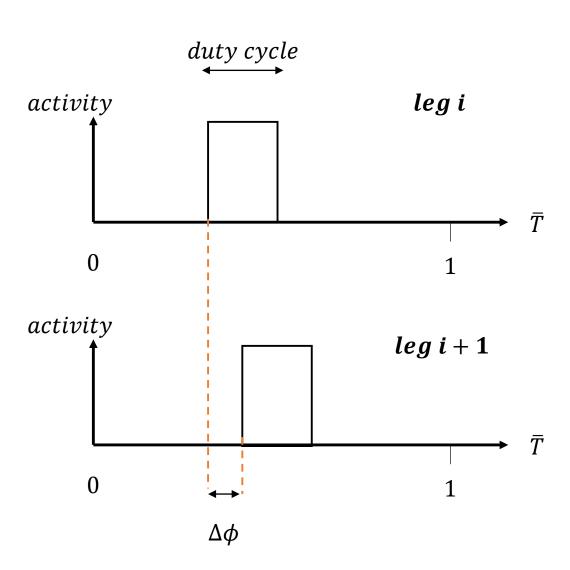
$$\lambda = -(\mathbf{J}_c \mathbf{M}^{-1} \mathbf{J}_c^T)^{-1} (\mathbf{J}_c \mathbf{M}^{-1} \mathbf{F} + \boldsymbol{\xi})$$

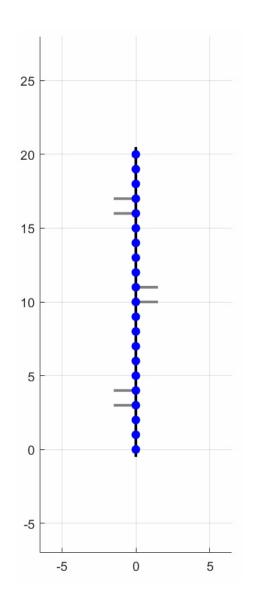
- Massless legs
- Inelastic impact upon foot placement $\mathbf{u}^+ = [\mathbf{I} \mathbf{M}^{-1}\mathbf{J}_c^T(\mathbf{J}_c\mathbf{M}^{-1}\mathbf{J}_c^T)^{-1}\mathbf{J}_c]\mathbf{u}^-$
- No-slip condition at footholds
- Non-dimensional representation $(\bar{I}, \bar{T}, \bar{k}, \bar{d})$ by (m, l, f)

Leg kinematics

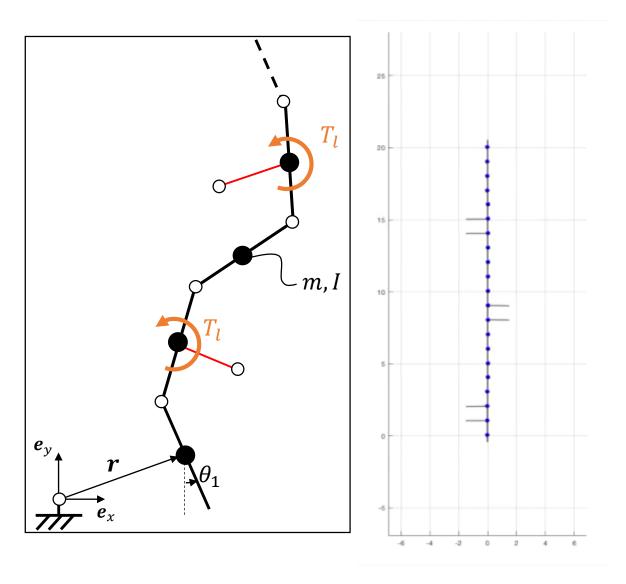


S. M. Manton, Zool. J. Linnean. Soc. 45,306-07 (1965).

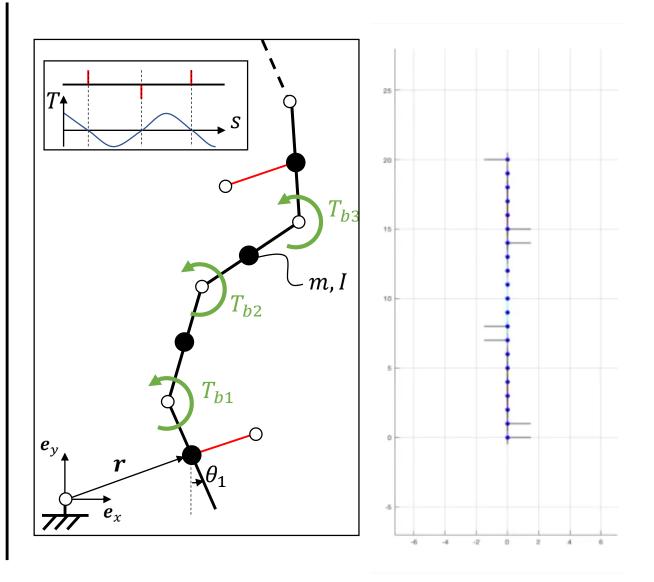




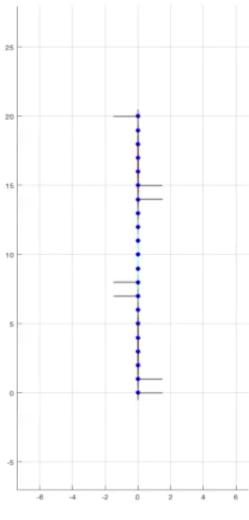
Leg actuation



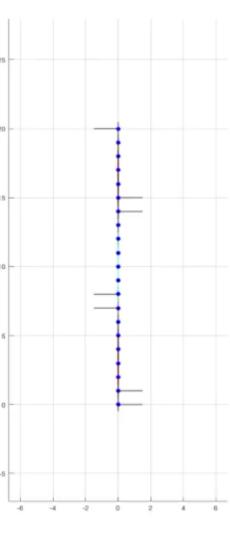
Bending actuation



Jamming

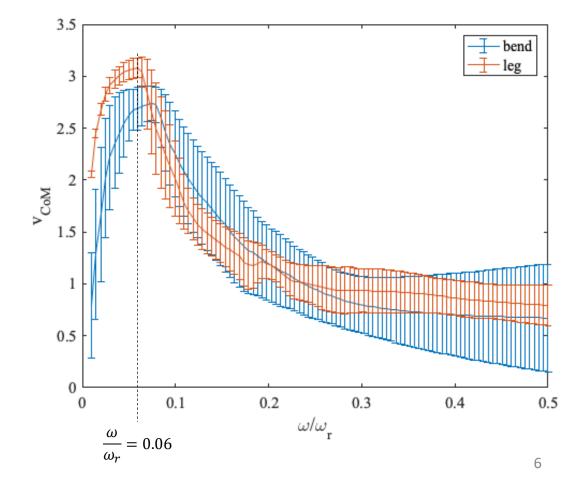


$$\bar{k}=0$$
, $\bar{d}=0$

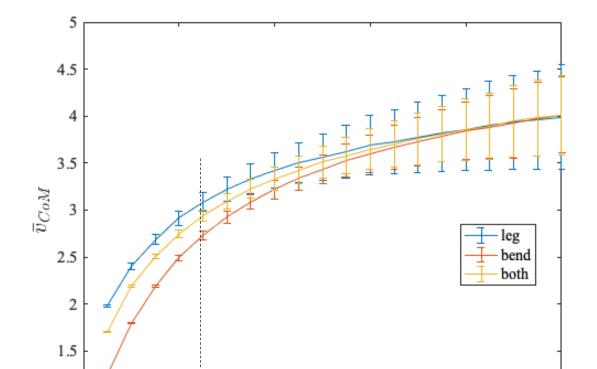


$$ar{k}=0$$
 , $ar{d}>0$

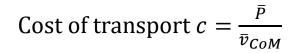
$$D = \frac{\bar{d}/2\bar{I}}{\sqrt{\bar{k}/\bar{I}}} = 3 \qquad \qquad \frac{\omega}{\omega_r} = \frac{\sqrt{\bar{T}/\bar{I}}}{\bar{d}/2\bar{I}}$$

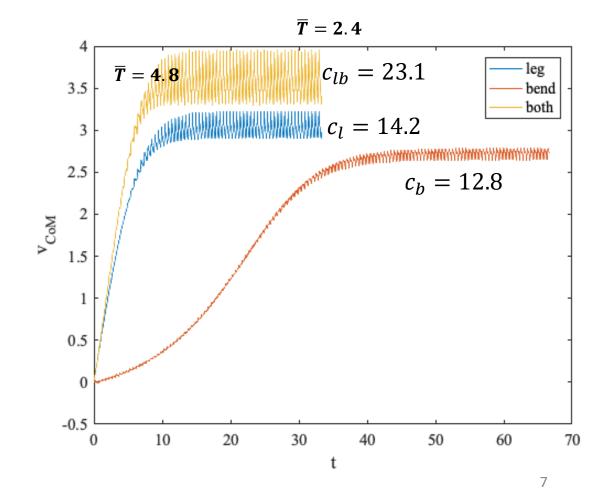


Superposition of actuation



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Conclusion

- (Manton, 1977): Undulations are due to stepping pattern and deleterious¹
- ➤ Undulations emerge by imposing stepping patterns
- Actively resisting undulations (high stiffness) leads to lower locomotion speed
- (Anderson, 1995): Undulations actively supported by muscles²
- Superimposing active bending on legged actuation increases speed and acceleration
- > ...but is energetically inefficient

